

## CLAIMS

1. A gait pattern generating device of a walking robot  
for generating a gait pattern from a desired ZMP trajectory  
5 using ZMP preview information, wherein

a driving quantity of the center of gravity in one  
moment is determined on the basis of a fed-back motion  
state of the center of gravity in the moment and a  
previewed or planned future ZMP trajectory, so as to  
10 generate a walking motion in real time.

2. The gait pattern generating device of a walking robot  
using ZMP preview information according to Claim 1, wherein  
the walking robot is a bipedal walking robot.

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3. The gait pattern generating device of a walking robot  
using ZMP preview information according to Claim 1 or 2,  
wherein

the previewed or planned future ZMP trajectory is  
20 corrected based on a detailed dynamical model of the robot  
in addition to a basic model using a table-cart model.